

CORRECTED VERSION

(19) World Intellectual Property  
Organization  
International Bureau



(43) International Publication Date  
27 January 2005 (27.01.2005)

PCT

(10) International Publication Number  
**WO 2005/007554 A1**

(51) International Patent Classification<sup>7</sup>: **B66C 13/06**

HYTÖNEN, Kimmo [FI/FI]; Uudenmaankatu 110 A 8,  
FIN-05840 Hyvinkää (FI).

(21) International Application Number:  
PCT/FI2004/000458

(74) Agent: **KOLSTER OY AB**; Iso Roobertinkatu 23, P.O.  
Box 148, FIN-00121 Helsinki (FI).

(22) International Filing Date: 16 July 2004 (16.07.2004)

(81) Designated States (unless otherwise indicated, for every  
kind of national protection available): AE, AG, AL, AM,  
AT, AU, AZ, BA, BB, BG, BR, BW, BY, BZ, CA, CH, CN,  
CO, CR, CU, CZ, DE, DK, DM, DZ, EC, EE, EG, ES, FI,  
GB, GD, GE, GH, GM, HR, HU, ID, IL, IN, IS, JP, KE,  
KG, KP, KR, KZ, LC, LK, LR, LS, LT, LU, LV, MA, MD,  
MG, MK, MN, MW, MX, MZ, NA, NI, NO, NZ, OM, PG,  
PH, PL, PT, RO, RU, SC, SD, SE, SG, SK, SL, SY, TJ, TM,  
TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, YU, ZA, ZM,  
ZW.

(25) Filing Language: English

(26) Publication Language: English

(30) Priority Data:  
20031087 17 July 2003 (17.07.2003) FI

(71) Applicant (for all designated States except US): **KCI  
KONECRANES PLC** [FI/FI]; Koneenkatu 8, FIN-05830  
Hyvinkää (FI).

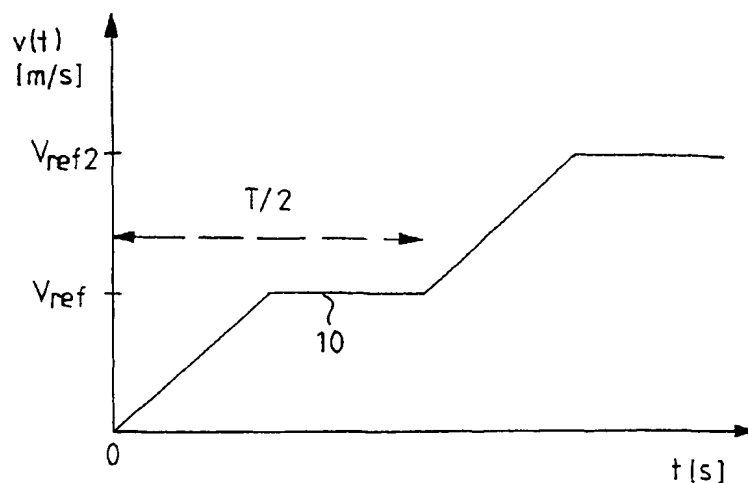
(72) Inventors; and

(75) Inventors/Applicants (for US only): **PORMA, Mikko**  
[FI/FI]; Kaivopolku 4 A 4, FI-01350 Vantaa (FI).

(84) Designated States (unless otherwise indicated, for every  
kind of regional protection available): ARIPO (BW, GH,  
GM, KE, LS, MW, MZ, NA, SD, SL, SZ, TZ, UG, ZM,  
ZW), Eurasian (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM),  
European (AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI,

[Continued on next page]

(54) Title: METHOD FOR CONTROLLING A CRANE



(57) Abstract: The invention relates to a method for controlling a crane, the method comprising comparing velocity requests ( $V_{ref}$ ) given by a crane control system with a previous velocity request and, if the velocity request is changed, forming and storing an acceleration sequence for the corresponding velocity change, summing the velocity changes defined by the stored acceleration sequences at a particular time and adding the obtained sum ( $dV$ ) to the previous velocity request to achieve a new velocity request ( $V_{ref2}$ ), which is set as a new control and velocity request for the crane drives (11, 12), and performing some of the velocity changes defined by the summed acceleration sequences at the definition time of each selected sequence on each program round, i.e. control step, and performing the rest of them as delayed in such a manner that the stored sequence parts to be performed as delayed are read and summed on a plurality of program rounds.